

**Amendments to the Claims:**

This listing of claims will replace all prior versions, and listings, of claims in the application:

Claims 1-45 (Cancelled)

46. (Cancelled)

47. (Currently Amended) The apparatus of claim [[46]] 68, wherein the manipulandum is a rotatable knob.

48. (Currently Amended) The apparatus of claim [[46]] 68, wherein the predetermined time-based force signal comprises a single time-based waveform.

49. (Currently Amended) The apparatus of claim [[46]] 68, wherein the predetermined time-based force signal comprises a plurality of time-based waveforms.

50. (Currently Amended) The apparatus of claim [[46]] 68, wherein the predetermined time-based force signal is represented by at least one of: a saw tooth wave, a square wave, a pulse, a full sine wave, a half sine wave, or a triangle wave.

51. (Currently Amended) The apparatus of claim [[46]] 68, wherein the manipulandum is a depressible button of a communication device.

52. (Currently Amended) The apparatus of claim [[46]] 68, wherein the manipulandum is a depressible button of a video game controller.

53. (Currently Amended) The apparatus of claim [[46]] 68, wherein the manipulandum is a depressible button of a computer mouse.

54. (Previously Presented) A method for outputting haptic sensation, comprising:  
sensing movement of a manipulandum between a first position and a second position of a detent;

outputting a position-based force signal to an actuator coupled to the manipulandum, the position-based force signal associated with the manipulandum being sensed from the first position to the second position;

outputting a first haptic feedback force via the actuator upon receiving the position-based force signal when the manipulandum is moving between the first and second positions; and

outputting a second haptic feedback force via the actuator only once upon sensing the manipulandum at a threshold position between the first and second positions, the second haptic feedback including a predetermined time-based force signal.

55. (Previously Presented) The method of claim 54, wherein the second haptic feedback force includes the position-based force signal.

56. (Previously Presented) The method of claim 54, wherein the predetermined time-based force signal is associated with a predetermined time-based waveform.

57. (Previously Presented) The method of claim 54, further comprising:  
outputting a biasing force configured to oppose movement of the manipulandum from the first position to the second position.

58. (Previously Presented) The method of claim 54, further comprising:  
accessing the predetermined time-based force signal stored within a processor-readable medium in response to sensing the manipulandum at the threshold position.

59. (Previously Presented) The method of claim 54, further comprising:  
outputting a biasing force configured to oppose the manipulandum being moved from the first position to the second position using a virtual spring.

60. (Previously Presented) The method of claim 54, further comprising:

outputting a biasing force configured to oppose the manipulandum being moved from the first position to the second position using a physical spring.

61. (Previously Presented) The method of claim 54, further comprising:  
outputting a biasing force configured to oppose the manipulandum being moved from the first position to the second position; and

outputting a third haptic feedback force in response to sensing the manipulandum being moved from the second position to the first position.

62. (Previously Presented) The method of claim 54, further comprising:  
determining a velocity at which the manipulandum is moved between the first and second positions; and

modifying a characteristic of the first haptic feedback force in response to the velocity of the manipulandum.

63. (Previously Presented) The method of claim 54, wherein the predetermined time-based force signal includes a plurality of predetermined time-based waveforms.

64. (Previously Presented) The method of claim 54, wherein the predetermined time-based force signal includes a single predetermined time-based waveform.

65. (Previously Presented) The method of claim 54, wherein the predetermined time-based force signal has a period in a range of about 1 ms to about 300 ms.

66. (Previously Presented) The method of claim 54, further comprising:  
selecting a predetermined time-based waveform associated with the predetermined time-based force signal; and

inputting a signal associated with the selected predetermined time-based waveform into a controller, the controller configured to control the actuator based on the signal associated with the selected predetermined time-based waveform when the manipulandum is disposed at the threshold position.

67. (Previously Presented) The method of claim 54, further comprising:  
outputting a hysteresis effect when the manipulandum is disposed at the threshold position.
68. (Previously Presented) An apparatus, comprising:  
a manipulandum;  
a sensor configured to sense movement of the manipulandum between a first position and a second position of a detent, wherein the sensor is configured to output a positional signal when the manipulandum is sensed moving from the first position to the second position; and  
an actuator configured to output a first haptic feedback force to the manipulandum in response to the positional signal indicating the manipulandum moving between the first position and the second position, wherein the first haptic feedback force corresponds to a position based force signal, the actuator configured to output a second haptic feedback force to the manipulandum only once in response to the positional signal indicating the manipulandum at a threshold position between the first and second positions, the second haptic feedback force including the position based force signal and a predetermined time-based force signal.
69. (New) A method for outputting haptic sensation, comprising:  
sensing movement of a rotatable knob between a first position and a second position of a detent;  
outputting a position-based force signal to an actuator coupled to the knob, the position-based force signal associated with the manipulandum being sensed from the first position to the second position;  
outputting a first haptic feedback force via the actuator upon receiving the position-based force signal when the knob is rotating between the first and second positions; and  
outputting a second haptic feedback force via the actuator only once upon sensing the knob at a threshold position between the first and second positions, the second haptic feedback including a predetermined time-based force signal.